

IN THE CLAIMS

This listing of claims will replace all prior versions, and listings, of claims in the application. An identifier indicating the status of each claim is provided.

Listing of Claims

1. (Original) A robot apparatus comprising:

sensor means for detecting an external or internal situation;

determination means for determining ~~based on~~ as a function of said external or internal situation and a corresponding serious level of the external or internal situation whether to ask for help,

wherein the serious level indicates ~~indicating~~ how serious the external or internal situation is for the robot itself; and

asking action selection means for selecting an action asking for help based on said external or internal situation and said serious level and making said robot apparatus take the action when said determination means decides to ask for help.

2. (Original) The robot apparatus according to claim 1, wherein

said asking action selection means selects another action asking for help and makes said robot apparatus take the action when said external or internal situation is not improved after asking for help.

3. (Original) The robot apparatus according to claim 1, wherein,

in a case where said external or internal situation is a critical situation with a high serious level, said asking action selection means changes a robot mode so as to delay progress of the critical situation when the external or internal situation is not improved after asking for help.

4. (Original) The robot apparatus according to claim 1, further comprising storage means for storing a log of past actions asking for help and their results, wherein said asking action selection means selects said action asking for help based on said external or internal situation and said serious level by reference to the log being stored in said storage means and makes said robot apparatus take the action when said determination means decides to ask for help.

5. (Original) A control method of a robot apparatus comprising:
a first step of detecting an external or internal situation and determining as a function of ~~based on~~ the external or internal situation and a corresponding ~~an~~ serious level of the external or internal situation whether to ask for help,

wherein the serious level indicates ~~indicating~~ how serious the external or internal situation is for the robot itself; and

a second step of selecting an action asking for help based on said external or internal situation and said serious level and making said robot apparatus take the action when said determination means decides to ask for help.

6. (Original) The control method according to claim 5, further comprising
a third step of selecting another action asking for help and making said
robot apparatus take the action when the external or internal situation is not improved after
asking for help.

7. (Original) The control method according to claims 5, wherein,
in a case where said external or internal situation is a critical situation with
a high serious level, said second step changes a robot mode so as to delay progress of the critical
situation when the external or internal situation is not improved after asking for help.

8. (Original) The control method according to claim 5, further comprising
a fourth step of storing a log of past actions asking for help and their
results, wherein
said second step selects an action asking for help based on said external or
internal situation and said serious level by reference to said log and makes said robot apparatus
take the action.